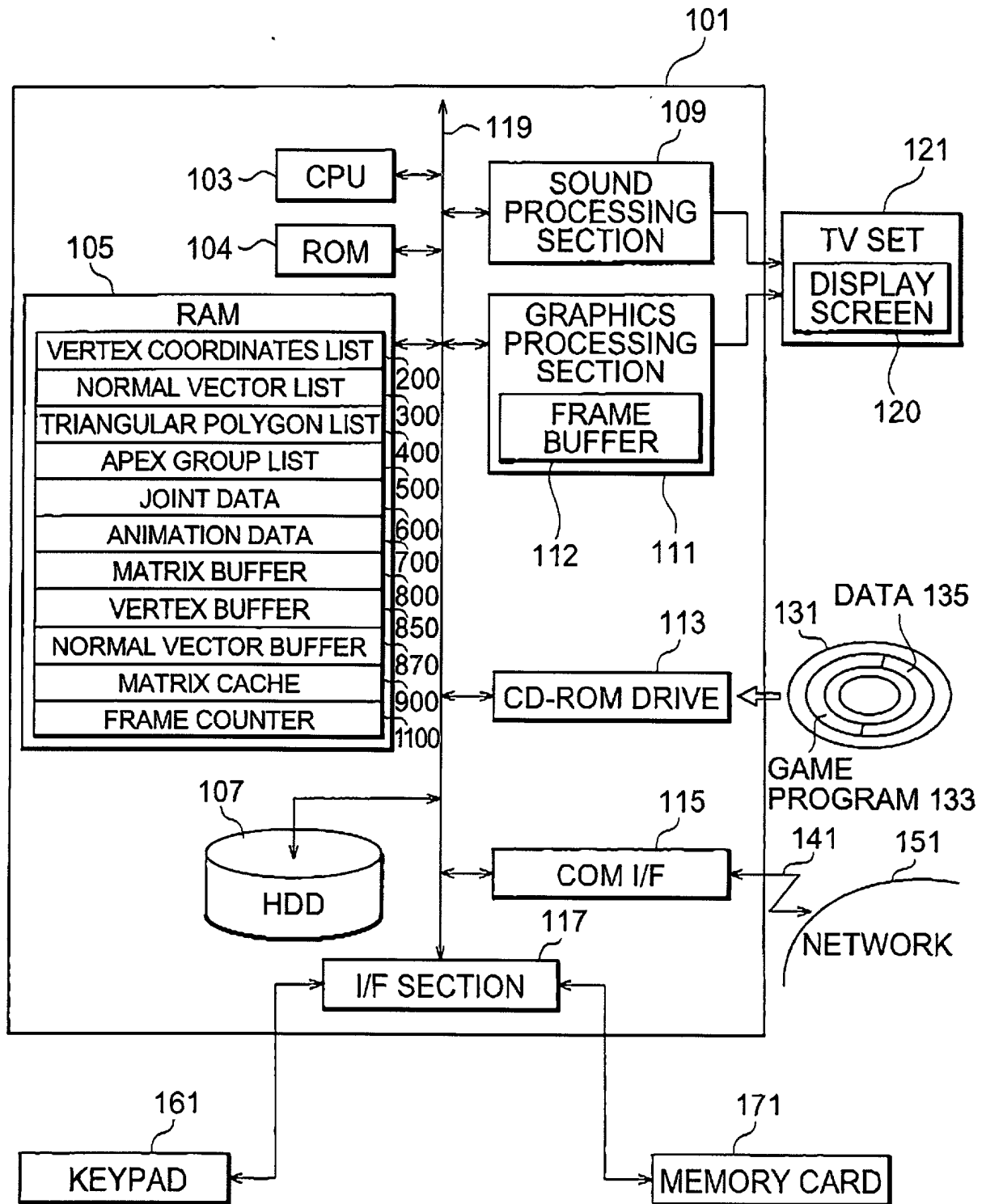


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**Fig.1**

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**Fig.2**

210 200 220

INDEX	COORDINATES (x,y,z)
vtx0	( 0 , 0 , 0 )
vtx1	( 0 , 0 , 100 )
vtx2	( 0 , 100 , 0 )
vtx3	( 0 , 100 , 100 )
vtx4	( 100 , 0 , 0 )
⋮	⋮

**Fig.3**

310 300 320

INDEX	NORMAL VECTOR (x,y,z)
nml0	( 1 , 0 , 0 )
nml1	( -1 , 0 , 0 )
nml2	( 0 , 0 , -1 )
nml3	( -1 , -1 , 0 )
nml4	( 0 , -1 , 0 )
⋮	⋮

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**Fig.4**

400

410 INDEX	420 VERTEX 0	430 VERTEX 1	440 VERTEX 2
plg0	vtx0 / nml0	vtx1 / nml2	vtx2 / nml3
plg1	vtx0 / nml1	vtx2 / nml3	vtx3 / nml4
⋮	⋮	⋮	⋮

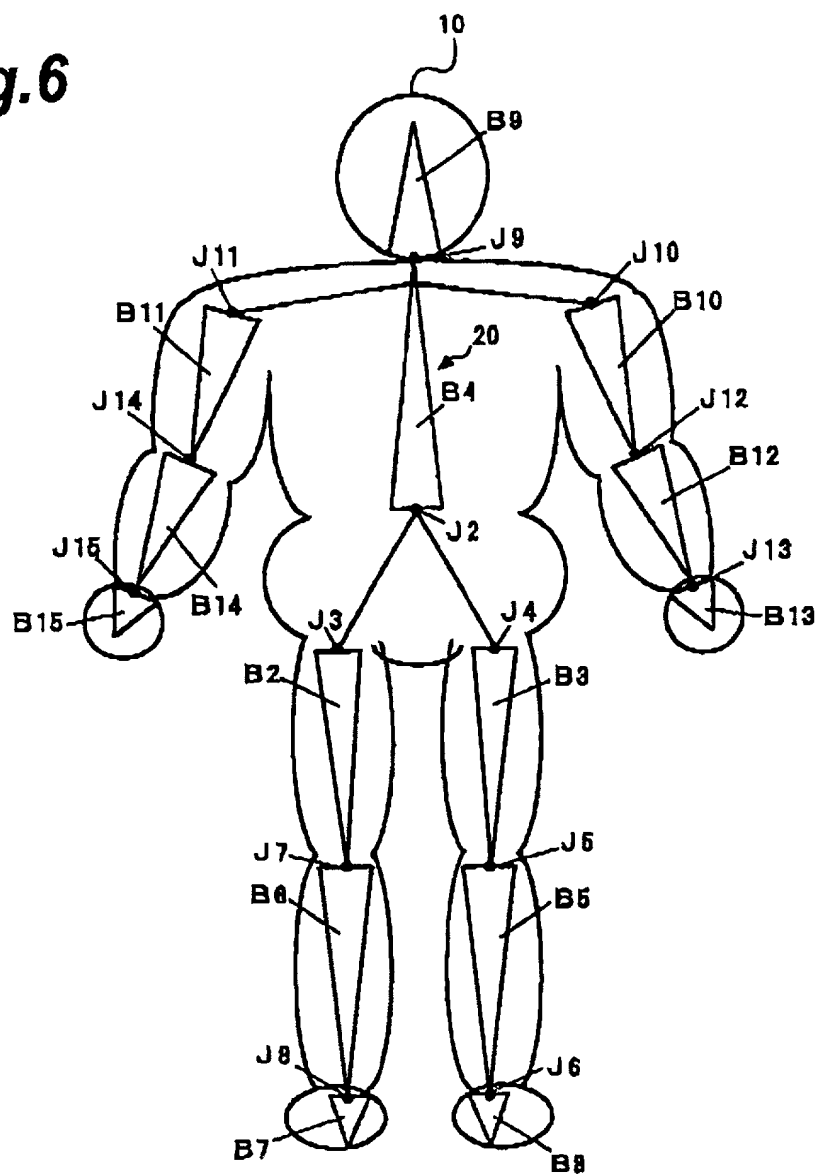
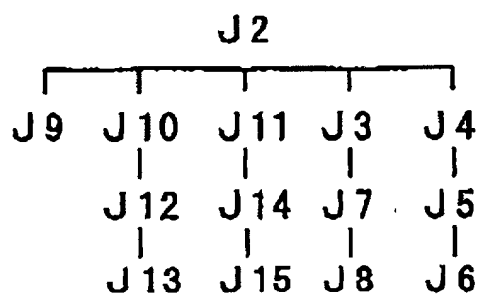
**Fig.5**

500

# VERTEX GROUP LIST

510	NUMBER OF GROUPS		3								
520	NUMBER OF MEMBERS		4								
530	VERTEX	vtx1	WEIGHT (540)	1.0	NUMBER OF NORMALS(570)	2	NORMALS (591)	nml0	nml1	VERTEX GROUP 0	
532	VERTEX	vtx2	WEIGHT (542)	1.0	NUMBER OF NORMALS(572)	1	NORMALS (592)	nml10			
534	VERTEX	vtx3	WEIGHT (544)	1.0	NUMBER OF NORMALS(574)	1	NORMALS (593)	nml2			
536	VERTEX	vtx4	WEIGHT (546)	1.0	NUMBER OF NORMALS(576)	2	NORMALS (594)	nml3	nml1		
522	NUMBER OF MEMBERS		4								
550	VERTEX	vtx5	WEIGHT (560)	0.5	NUMBER OF NORMALS(580)	1	NORMALS (595)	nml11		VERTEX GROUP 1	
552	VERTEX	vtx6	WEIGHT (562)	0.5	NUMBER OF NORMALS(582)	1	NORMALS (596)	nml4			
554	VERTEX	vtx7	WEIGHT (564)	1.0	NUMBER OF NORMALS(584)	1	NORMALS (597)	nml5			
556	VERTEX	vtx8	WEIGHT (566)	1.0	NUMBER OF NORMALS(586)	3	NORMALS (598)	nml6	nml8	nml9	VERTEX GROUP 2
524	NUMBER OF MEMBERS		1								
558	VERTEX	vtx7	WEIGHT (568)	0.5	NUMBER OF NORMALS(588)	1	NORMALS (599)	nml7			

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**Fig.6****Fig.7**

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**Fig.8**

600

610	Root index	root	
612	Basic parallel movement amount (x, y, z)	(0, 0, 0)	
614	Basic Rotation angle (Rx, Ry, Rz)	(0, 0, 90)	
616	Number of joints	4	
620	Joint index	Joint0	Joint 0
622	Parent index	root	
624	Basic parallel movement amount (x, y, z)	(90, 20, 0)	
626	Basic Rotation angle (Rx, Ry, Rz)	(0, 0, 135)	
628	Number of vertex groups	2	
630	Vertex group number	0	
632	Vertex group number	2	
640	Joint index	Joint1	Joint 1
642	Parent index	Joint0	
644	Basic parallel movement amount (x, y, z)	(40, 0, 0)	
646	Basic Rotation angle (Rx, Ry, Rz)	(0, 0, 45)	
648	Number of vertex groups	1	
650	Vertex group number	1	

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**Fig.9A**

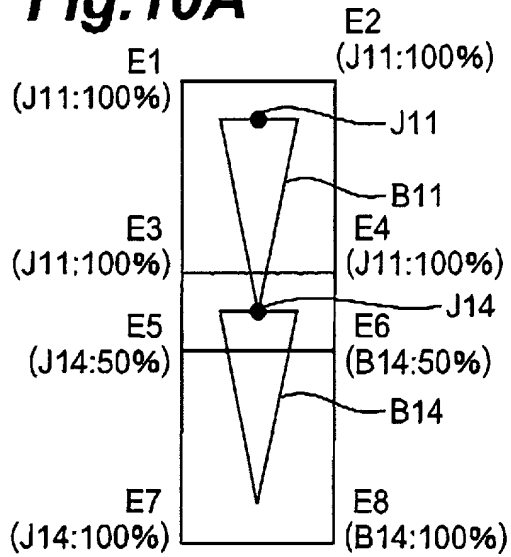
700	
710	720
Number of joints	Number of frames
2	10

**Fig.9B**

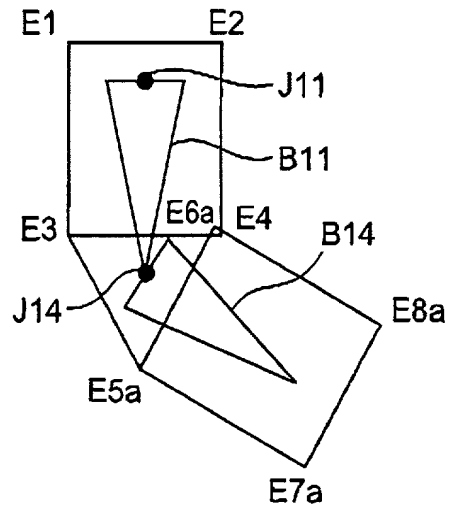
730		740		700	
Joint index	Rotation angle (Rx, Ry, Rz)				
Joint0	(0, 0, 0)		Frame0		
Joint1	(0, 0, 0)				
Joint0	(10, 0, 135)		Frame1		
Joint1	(-10, 5, 45)				
⋮	⋮				
Joint0	(90, 0, 150)		Frame9		
Joint1	(-90, 45, 45)				

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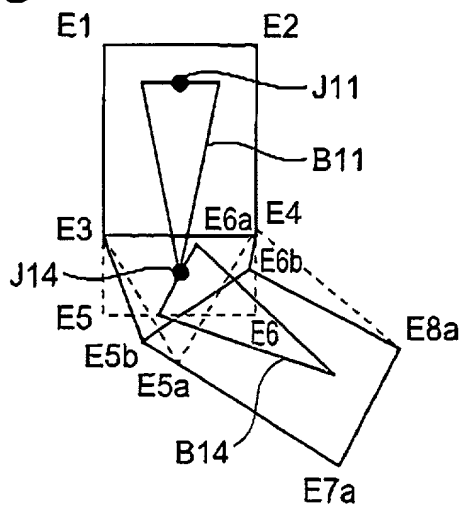
**Fig.10A**



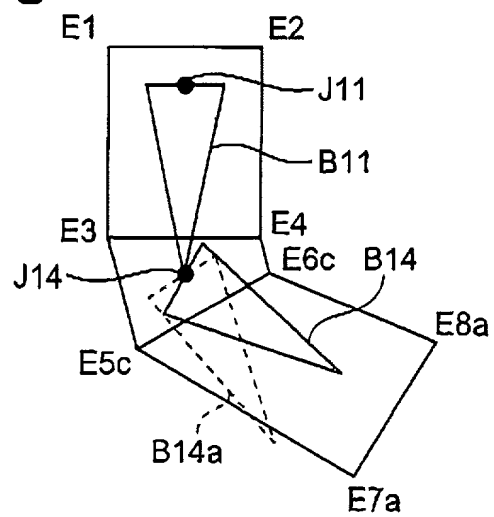
**Fig. 10B**



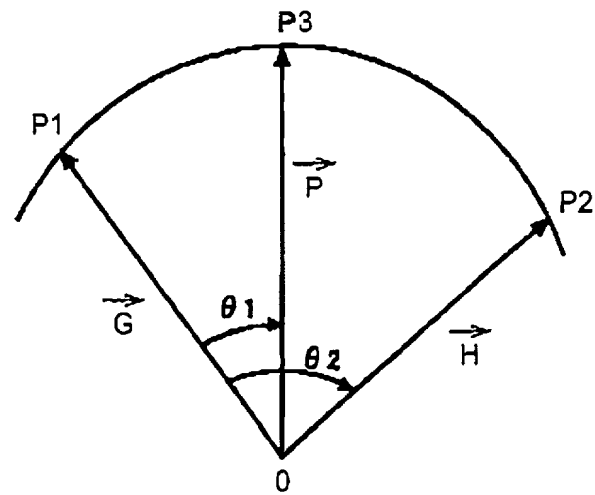
**Fig. 10C**



**Fig. 10D**



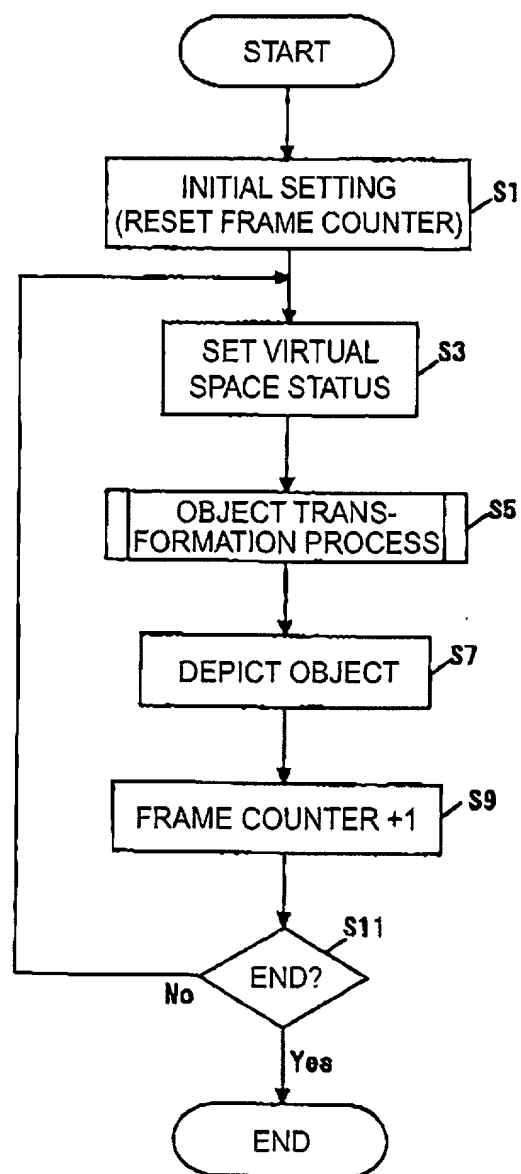
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**Fig.11**

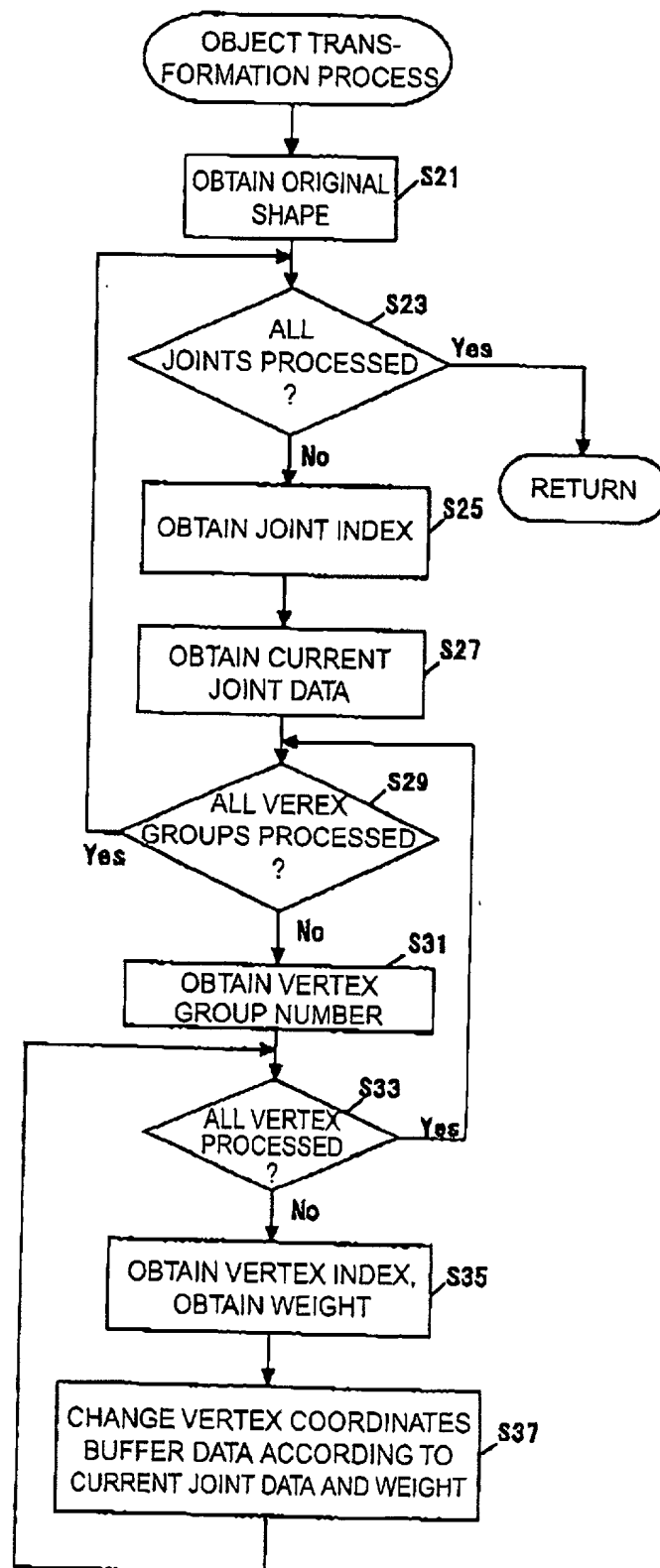
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**Fig.12**

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**Fig.13**

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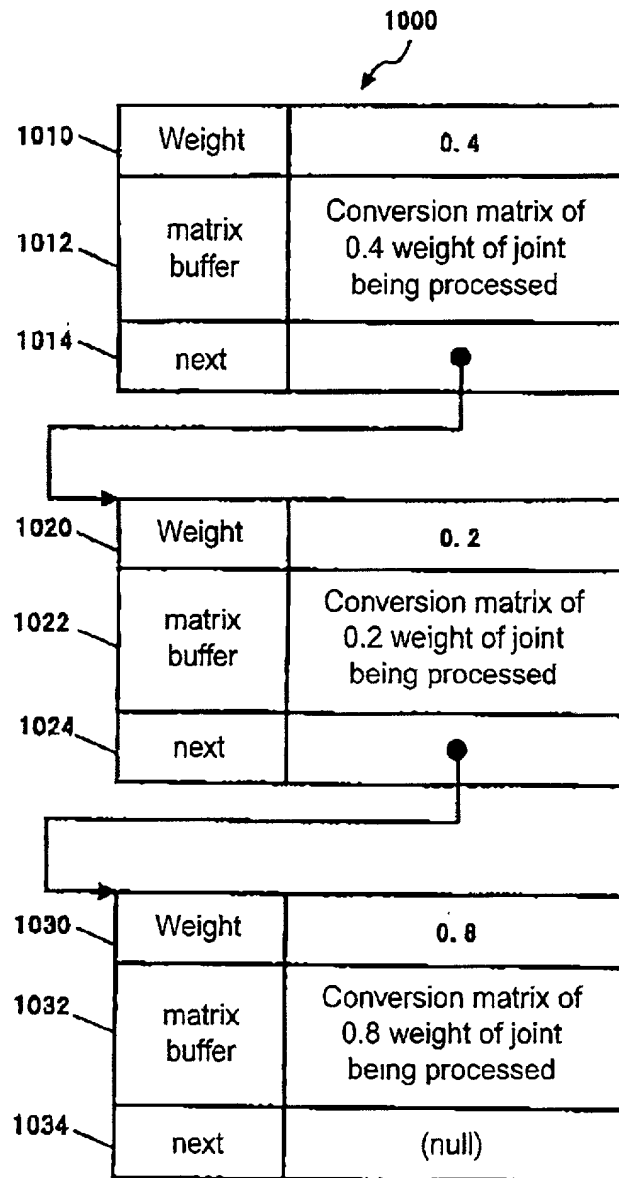
**Fig.14**

Joint index	Matrix data
root	Root conversion matrix
Joint0	Conversion matrix with 100% weight of joint0
Joint1	Conversion matrix with 100% weight of joint1

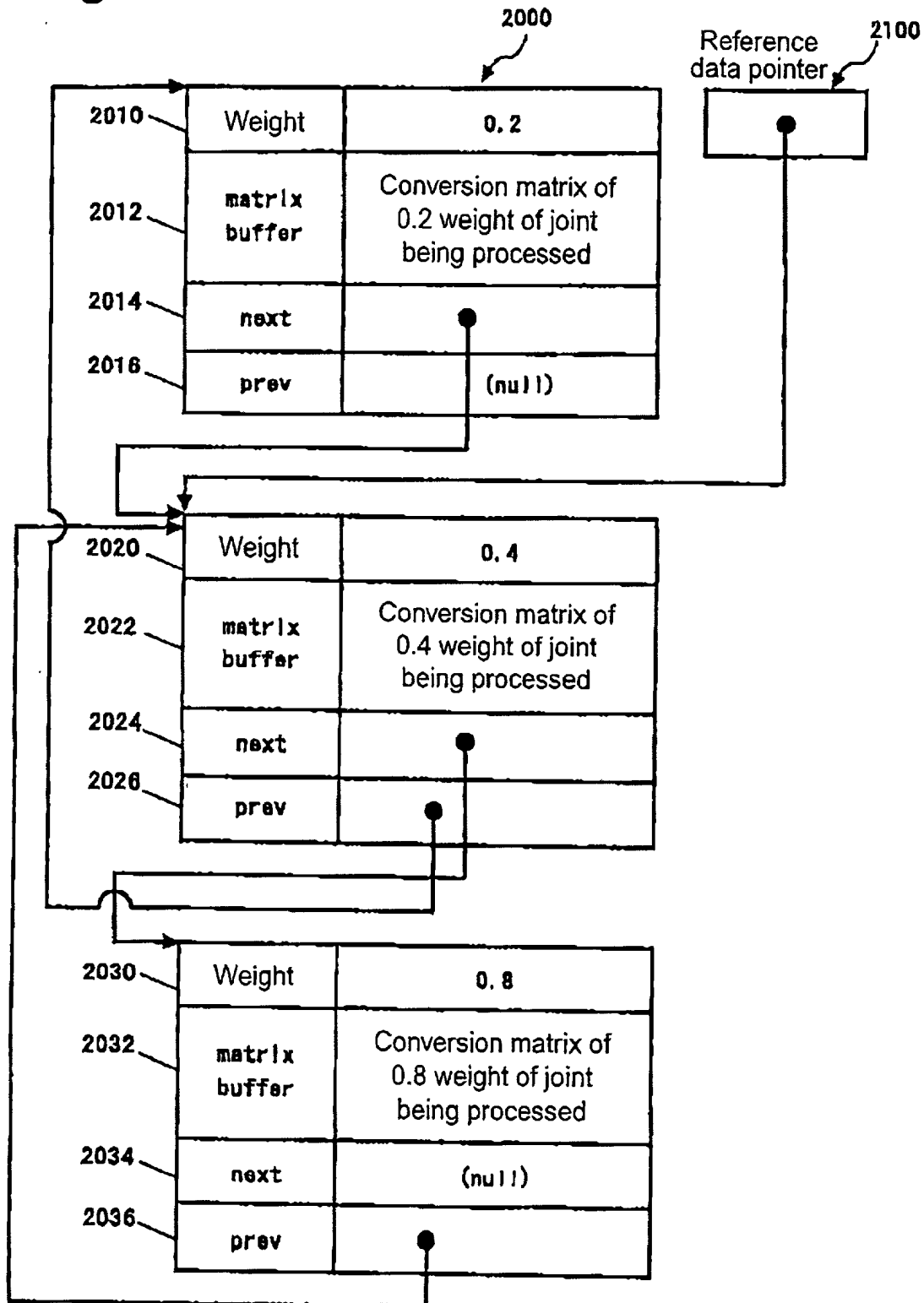
**Fig.15**

Weight	Weight
matrix buffer	Conversion matrix according to weight of joint being processed

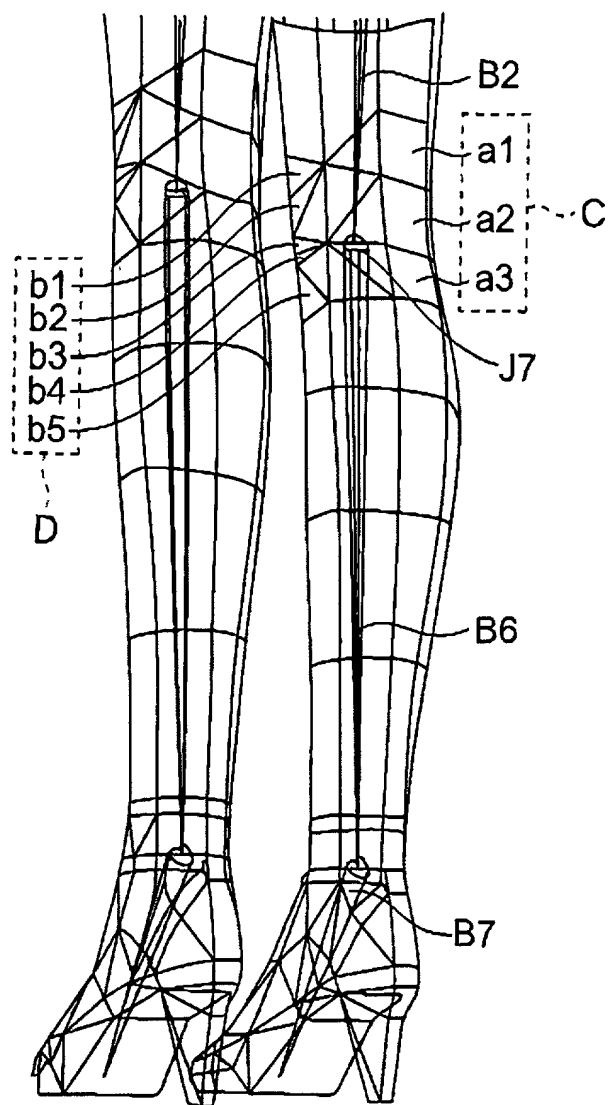
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**Fig.16**

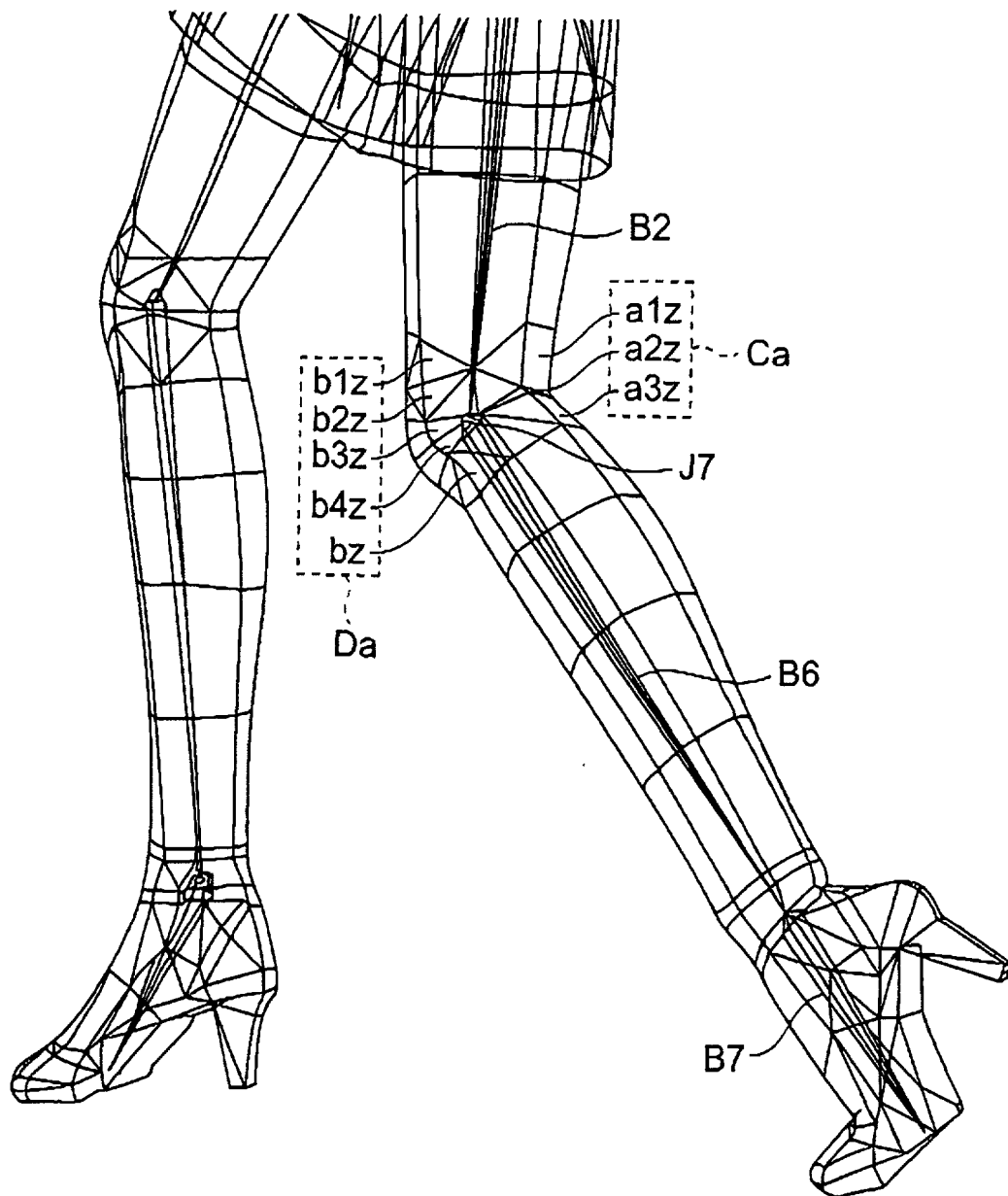
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**Fig.17**

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**Fig.18**

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**Fig.19**

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**Fig.20**



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**Fig.21**



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